

MrRoboto

1 How to setup system

If you're using the robot lab's computer skip to 1.3.

1.1 Initial computer settings

1. Install ubuntu 12.04 on your computer.
2. Install ROS GROOVY according to: <http://wiki.ros.org/groovy/Installation/Ubuntu>
3. Install git, type:
`$ sudo apt-get install git` (in a terminal window)
Password is *ubuntu* for the computer in the robot lab.
4. Clone the repository of the project. cd* into a folder where you want the folder containing the code. Type:
`$ git clone git@github.com:matni796/robot-security-tsbb11`
(*cd is a terminal command. If your not familiar with navigation in terminal, see http://linuxcommand.org/lc3_lts0020.php)
5. Source your own created packages in .bashrc: type: gedit /.bashrc add the line: `source wherever_path_you_put_repository/robotsecuritytsbb11/catkin_ws/src/devel/setup.bash`
6. Install ROS, type:
`$ sudo apt-get install ros-groovy-desktop-full`
7. Install freenect, type:
`$ sudo apt-get install ros-groovy-freenect-stack`
`$ sudo apt-get install ros-groovy-freenect-launch`
8. Install arm navigation (used for visualization)
`$ sudo apt-get install ros-groovy-arm-navigation-experimental`
9. Disable gspca kernel according to: http://openkinect.org/wiki/Getting_Started
10. cd into the installed folder and into catkin_ws and type catkin_make to build.

1.2 Setup of DX100 controller

1. Make sure the controller's version supports MotoPlus applications, should be a version ending with -14. Current version (20131206) is DS3.53.01A-14.
2. Load parameters. The file ALL.PRM can be found in git repo, under the folder robot/. Transfer it to a cf card or usb. Start the controller regularly. Go into management mode (see below). Then go to:

EX MEMORY → FOLDER, set folder where you put ALL.PRM.

EX MEMORY → LOAD → PARAMETERS → BATCH PARAMETERS
ALL.PRM

You might need to do a safety reset of the flash device. This is done by starting up the controller in Maintenance mode. In Maintenance Mode, enter Management mode. INITIALIZE → system flash safety reset, might take a while, wait for beep. Shut off controller and restart it regularly.

NOTE: Might change the setup of the controller. Should be done with caution. Contact Yaskawa if uncertain.

3. To install MotoPlus application, follow the tutorial on http://wiki.ros.org/motoman_driver/Tutorials/InstallServer.

- For step 3 in tutorial, see PDF file *MotoPlus Application Installation* in folder *robot/*. Follow the instructions on step 2.1. The application file: *MpRosSia20.out* to be loaded is also in the *robot/* folder.

NOTE: We have used an .out file hardcoded for a SIA20D robot. This version does not come with the motoman files from ROS.

- For step 4 in tutorial, transfer *INIT_ROS.JBI* to CF card or USB device. File can be found under *../catkin_ws/src/motoman/motoman_driver/Inform/DX100/*. Start the controller regularly. In menu, go to:

Ex MEMORY → FOLDER move to the folder where you put *INIT_ROS.JBI* file. Then:

Ex Memory → LOAD → job.

1.3 Setup of computer network settings

1. Connect the computer to the controller via ethernet cable. Use the output CN104 on the YCP01 board.
2. Edit settings for wired/local network on computer. Set computer wired network address to 192.168.255.9 and netmask 255.255.255.0.

NOTE: On the computer, running Ubuntu 12.04, in the robot lab, there is a profile for the connection named “DX100”. When connecting the controller to the computer via ethernet, choose this.

2 Run program

When the setup is done follow these instructions to run the system.

2.1 Establish connection between controller and computer

The complete instructions for establishing a connection with the controller can be found at: http://wiki.ros.org/motoman_driver/Tutorials/Usage. Run the following in a separate terminal. Hint: *Ctrl + Shift + T* opens a new tab.

- `$ roscore`
- `$ rospack load ...catkin_ws/src/motoman/motoman_config/cfg/sia20D_mesh.xml`
`robot_description`
- `$ roslaunch motoman_driver robot_interface_streaming_dx100.launch robot_ip:=192.168.255.1`

NOTE: Currently it is not possible to send motion commands to the robot. This is due to developers lack of implementation skills.

2.2 Launch system

While still running *roscore* and the robot node. Run the following comands, each in a separete terminal. Use *Ctrl+Shift+T* to add a tab to existing terminal window.

- `$ roslaunch freenect.launch freenect.launch`
- `$ rosrun background_modelling background_modelling`
- `$ rosrun clustering clustering`
- `$ rosrun calibration calibration`
- `$ rosrun distance_calc distance_calc`
- In order to set the static transform between the calibration pattern and the robot base. In terminal, type:
`$ rosrun tf static_transform_publisher x y z yaw pitch roll base_link pattern 100`
where x, y, z and yaw, pitch, roll has to be specified. With the setup in our project they were: $[0, 0, 0, \pi, \pi, \pi]$. This might need to be tweaked to get a good calibration.
- To obtain visualization, type:
`$ roslaunch sia20d_mesh_arm_navigation planning_scene_warehouse_viewer_sia20d_mesh.launch`
This will launch the visualisation environment RViz.

NOTE: In each terminal there will be data printed about that function's current state.

2.3 Visualization

RViz provides a wide range of possibilities for visualization. To begin with there are some fundamental settings that always needs to be performed.

- Under Global Options, choose `/base_link` as Fixed Frame.
- Add a PointCloud2 and choose `/objects` as Topic.
- For one of the Markers choose the Topic `/closest_line`
- Add a camera
 - Choose an image topic, preferably mono

- Set "overlay alpha" to 1
- Set queue size to 1
- Choose an appropriate image rendering.
Note: The camera matrix used for visualization is the default. The backprojection will not coincide perfectly with the image